AMENDMENTS TO THE SPECIFICATION

Page 1, 1st paragraph:

This application is based on Application No. 2000-363014, filed in Japan on November 11, 2000, the contents of which are hereby incorporated by reference. This application is also a divisional of parent Application No. 09/870,795 filed June 1, 2001, now US Patent No. 6,631,324; the disclosure of which is incorporated herein by reference.

Page 11, please delete the last full paragraph

Paragraph bridging pages 11 and 12:

Fig. ~~9(b)~~9 is a flow chart for explaining the details of the "vehicle tracking processing" according to the present invention.

Page 12, please delete the 1st full paragraph

Page 11, 2nd full paragraph:

Fig. ~~10(b)~~10 is a flow chart for explaining the details of the "moving vehicle detection processing" according to the present invention.

Paragraph bridging page 23 and page 24:

In step 606, the distance image obtained in steps 603 through 605 is projected to the X axis to form a histogram Xproj (m), as illustrated in Fig. 13. As the histogram is prepared in this manner, when the laser radar 100 is ~~detectingd~~detecting a side wall on a straight line road for instance, the detection points data, detecting the side wall, become a group of detection points arranged in the longitudinal direction, and hence, when seeing the distance image corresponding to the group of detection points in a histogram in which the distance image is projected to the X axis, a peak comes out at a side or lateral position X in which the side wall exists. Then, in